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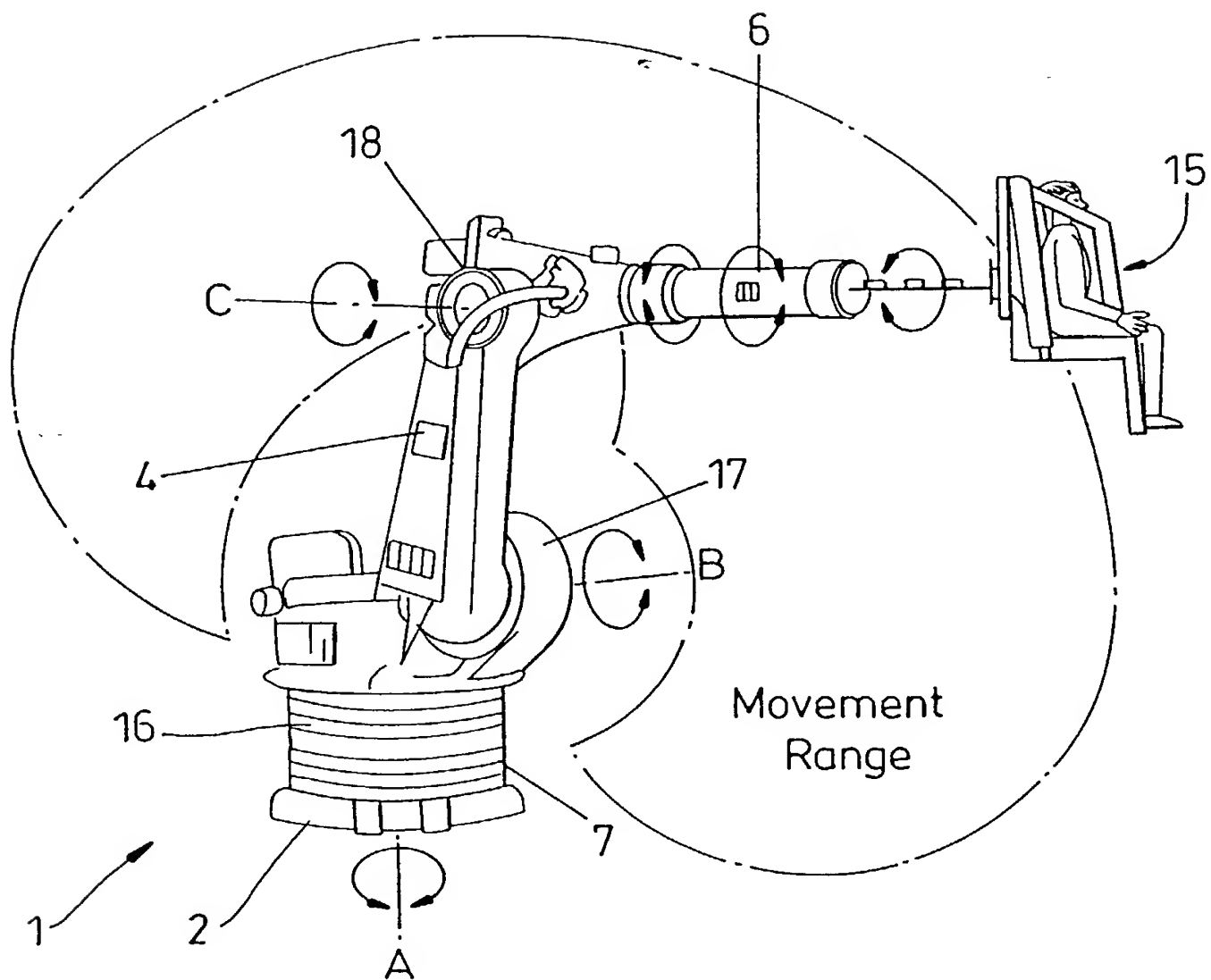


Fig. 1

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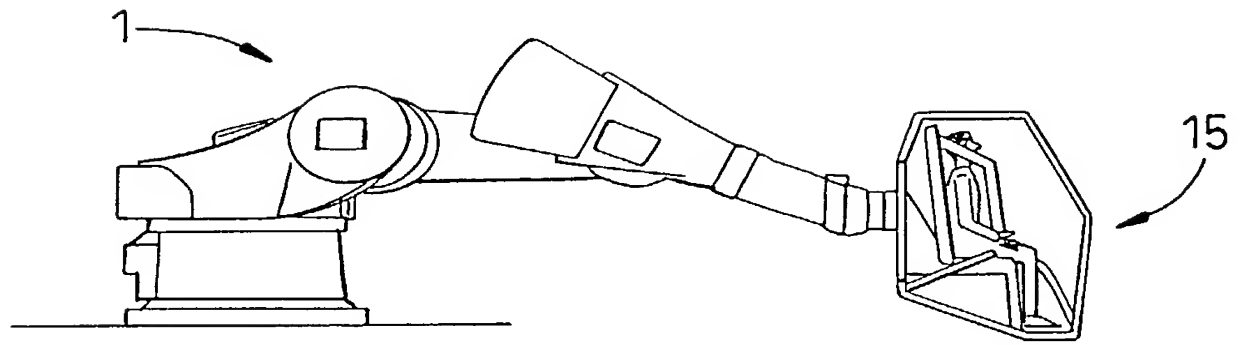


Fig. 2A

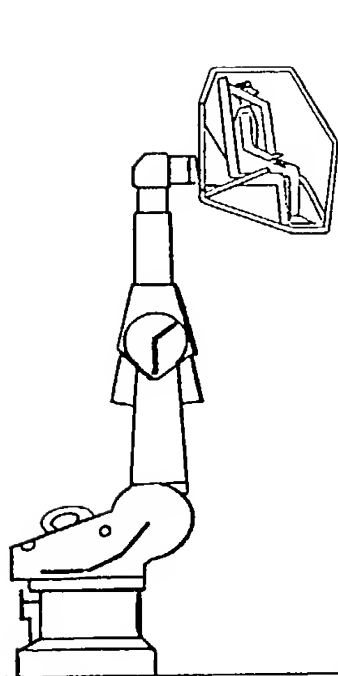


Fig. 2B

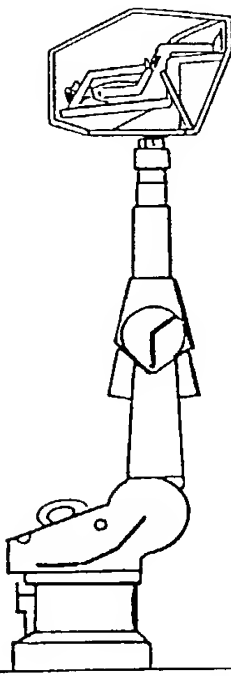


Fig. 2C

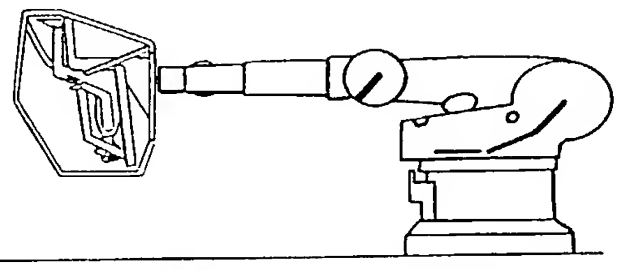


Fig. 2D

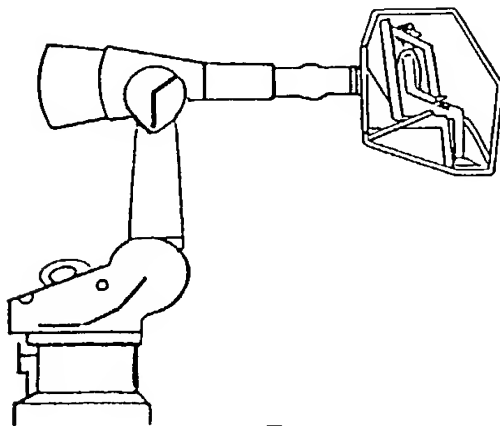


Fig. 2E

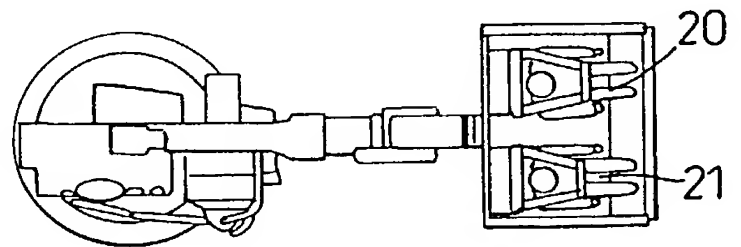


Fig. 2F

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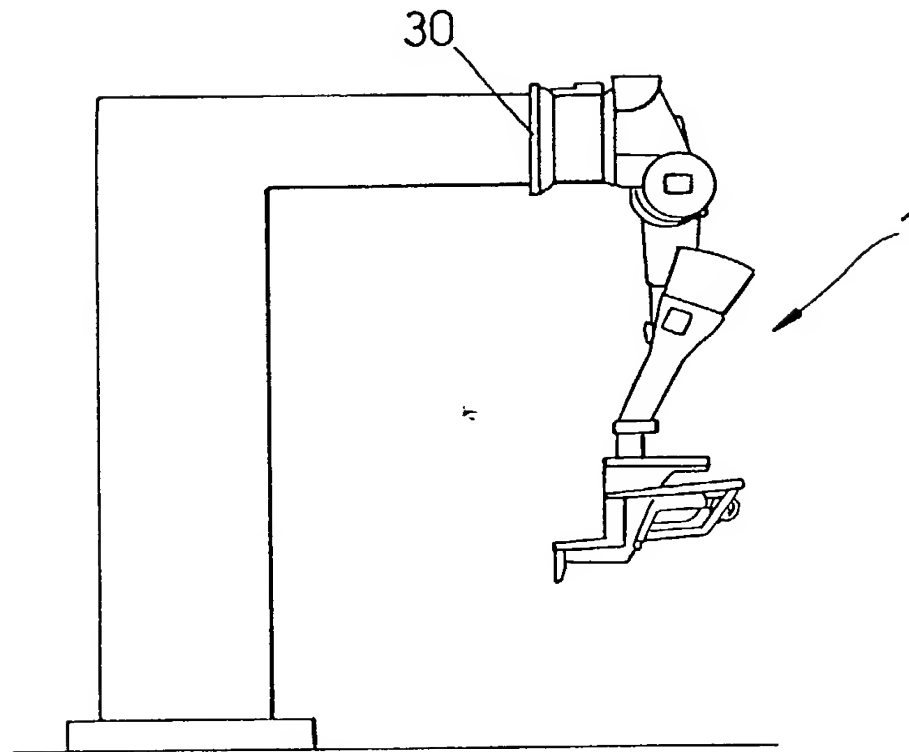


Fig. 3A

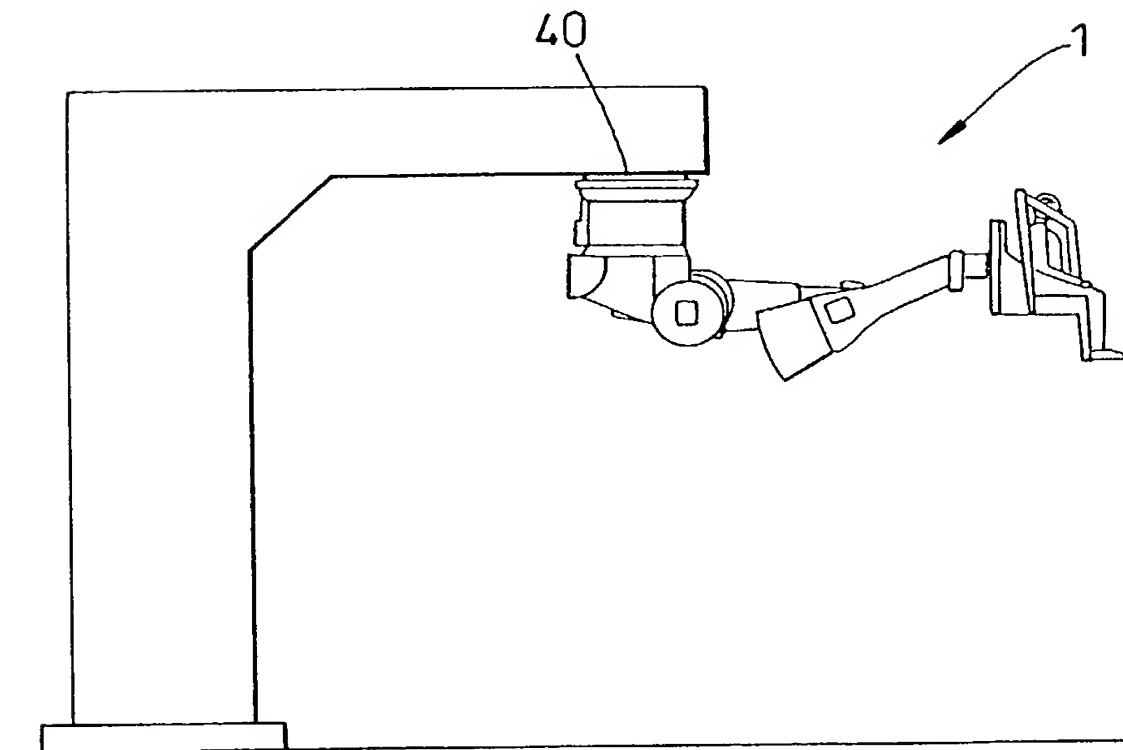


Fig. 3B

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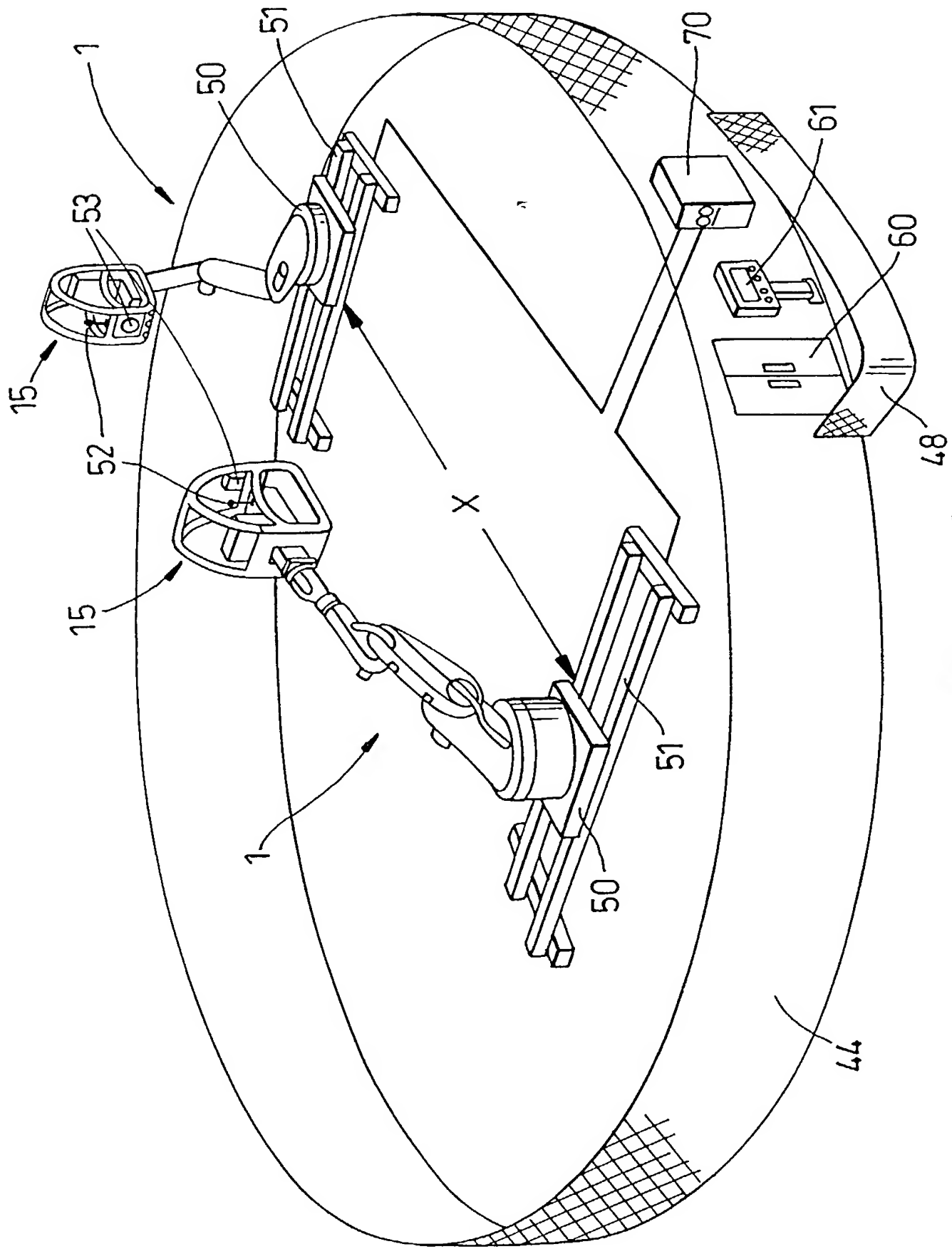


Fig. 4

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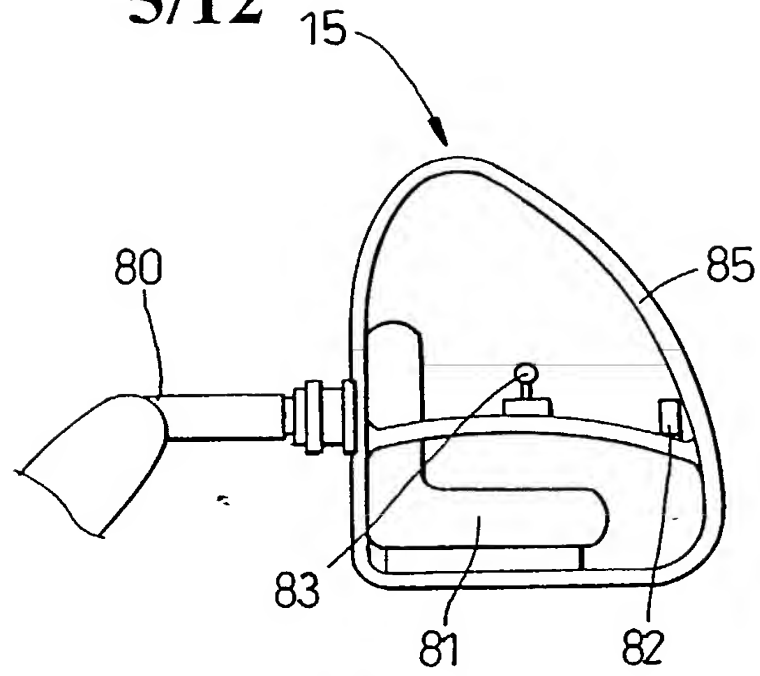


Fig. 5A

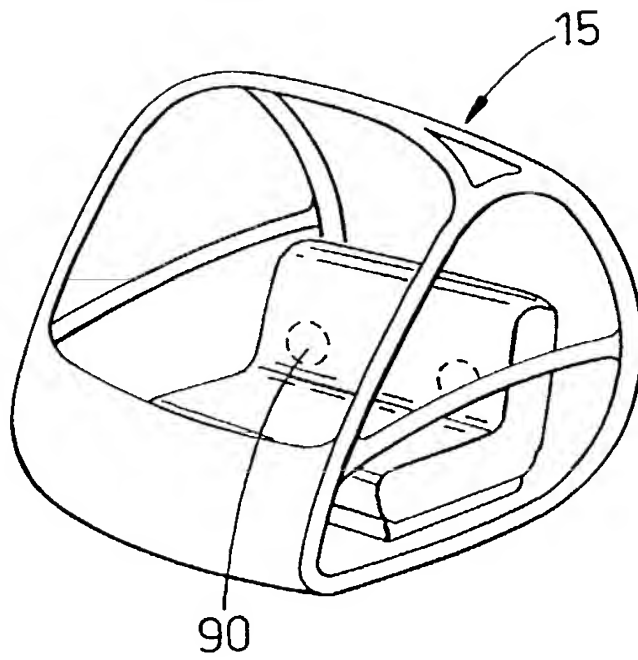


Fig. 5B

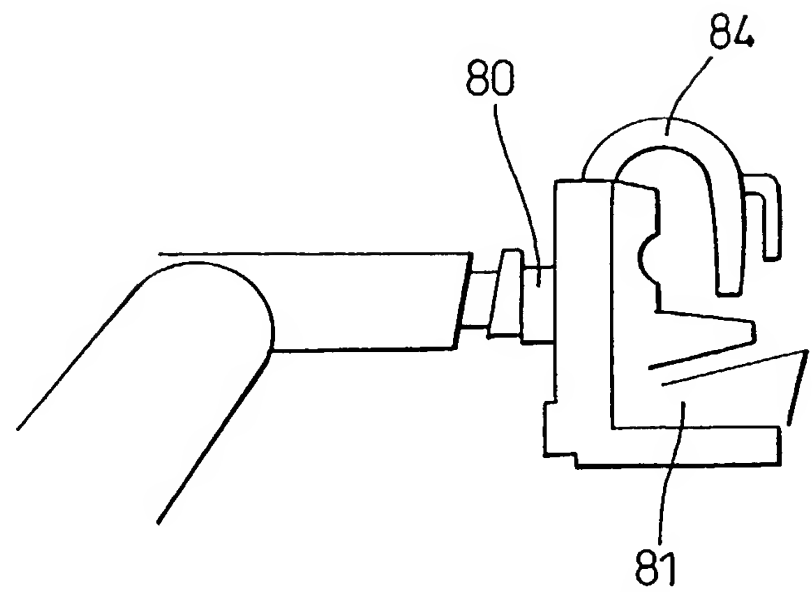
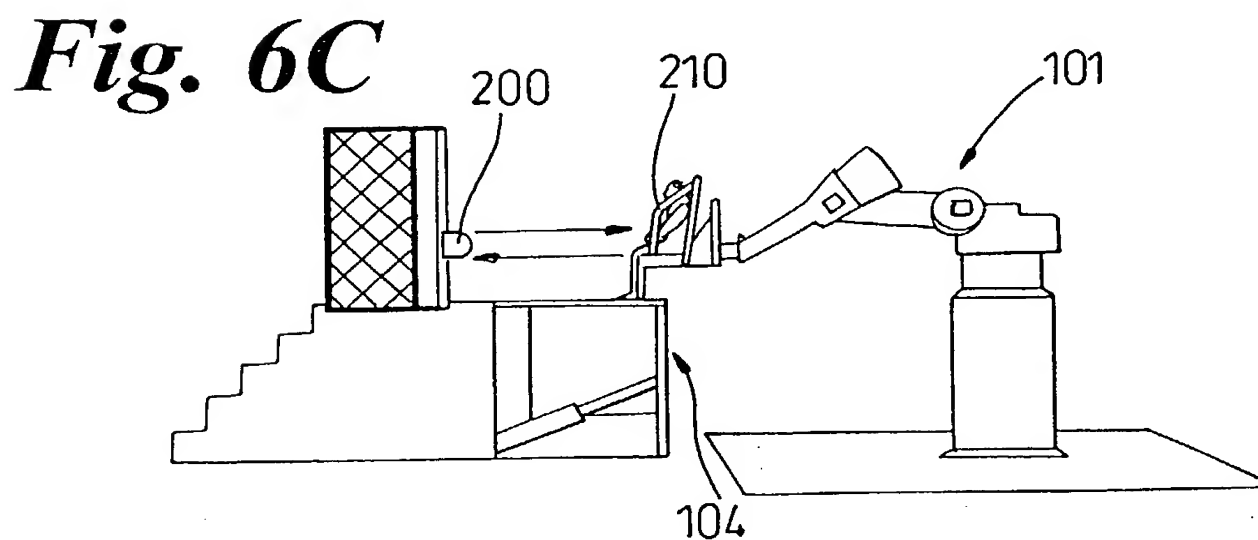
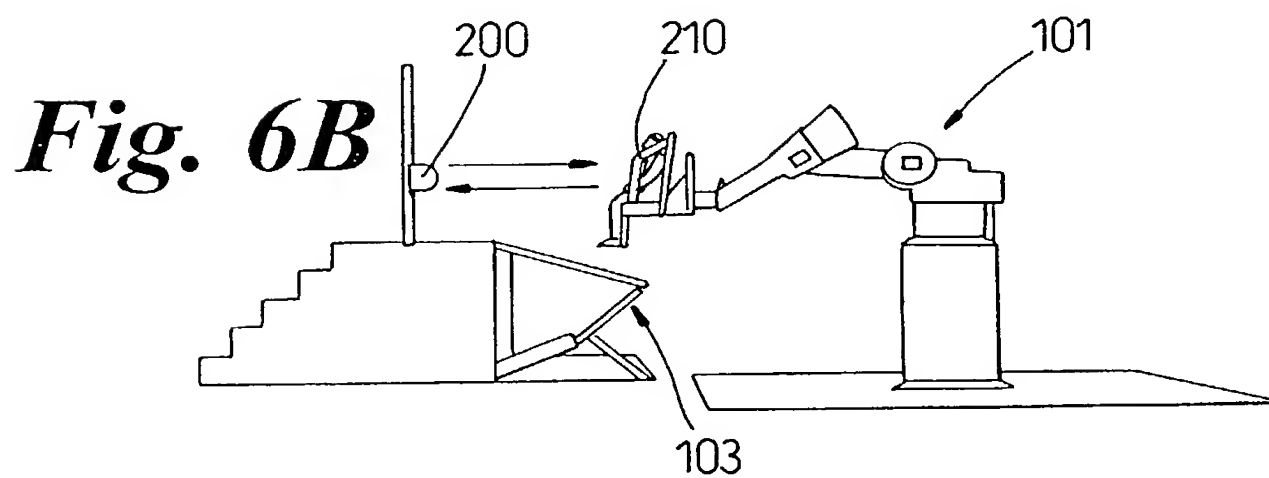
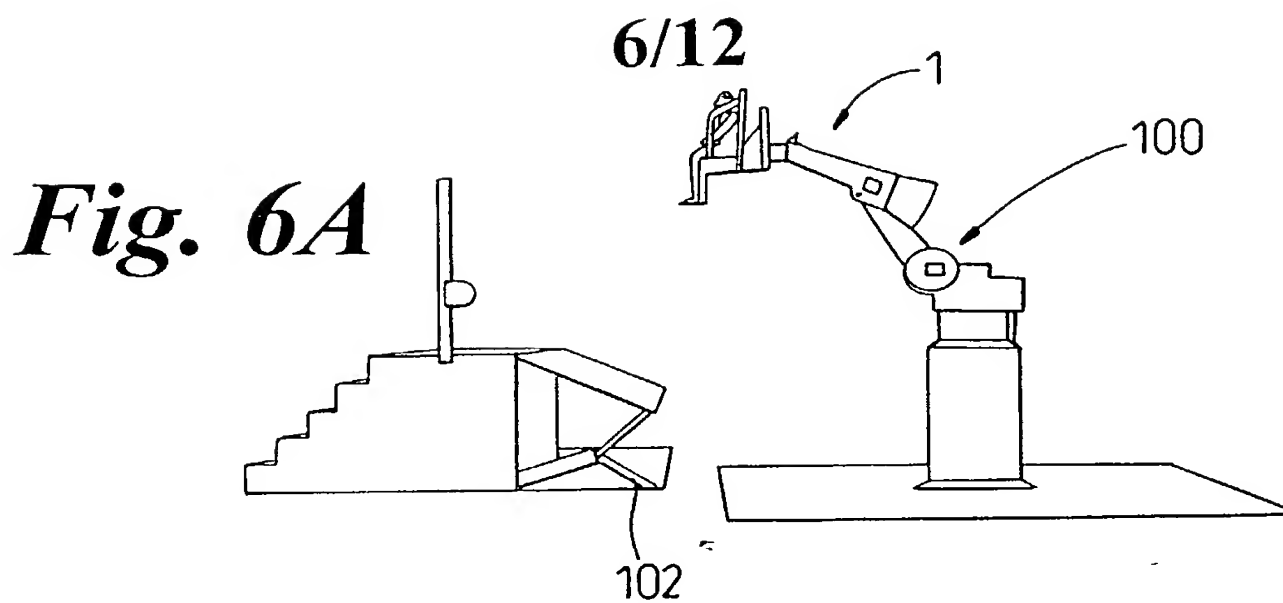


Fig. 5C



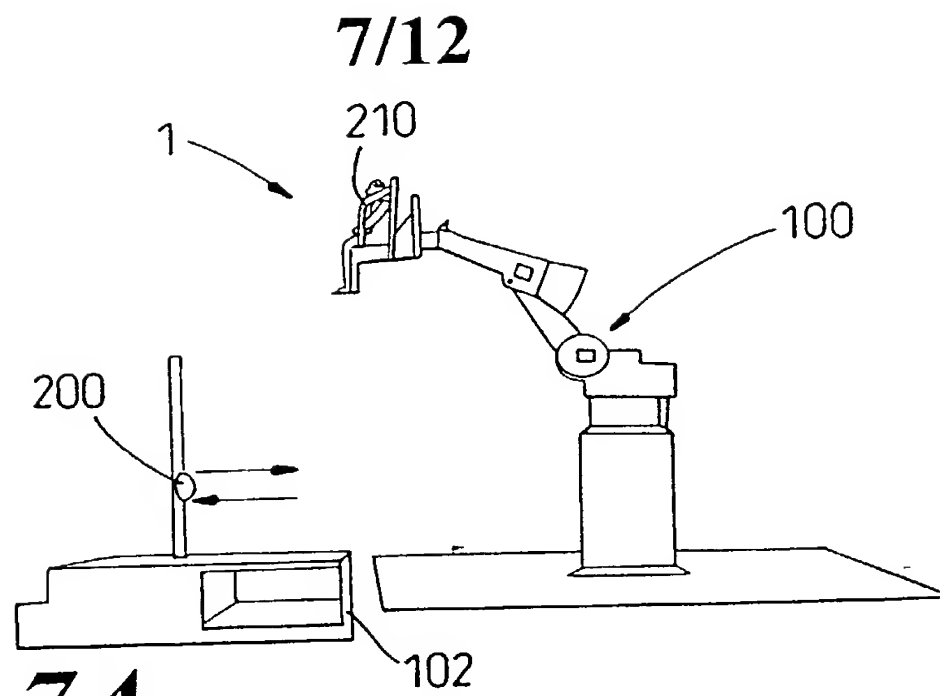


Fig. 7A

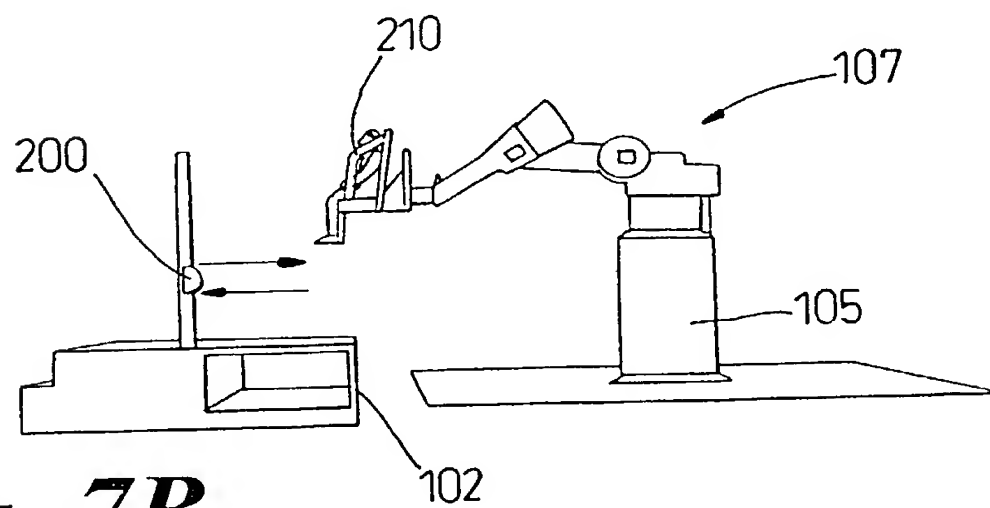


Fig. 7B

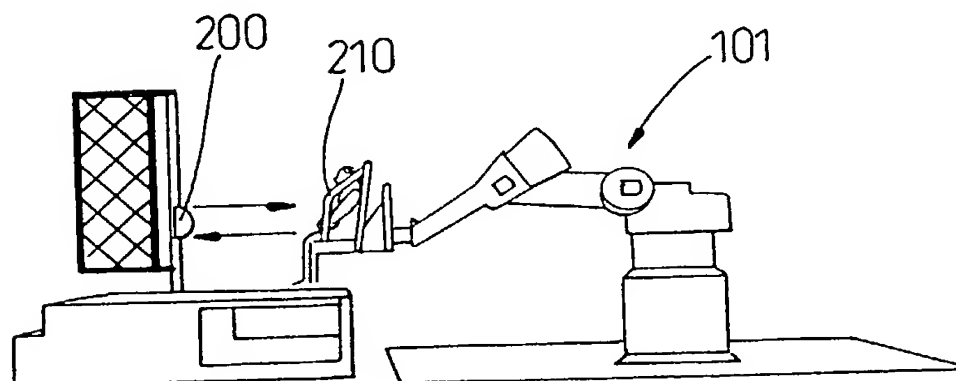


Fig. 7C

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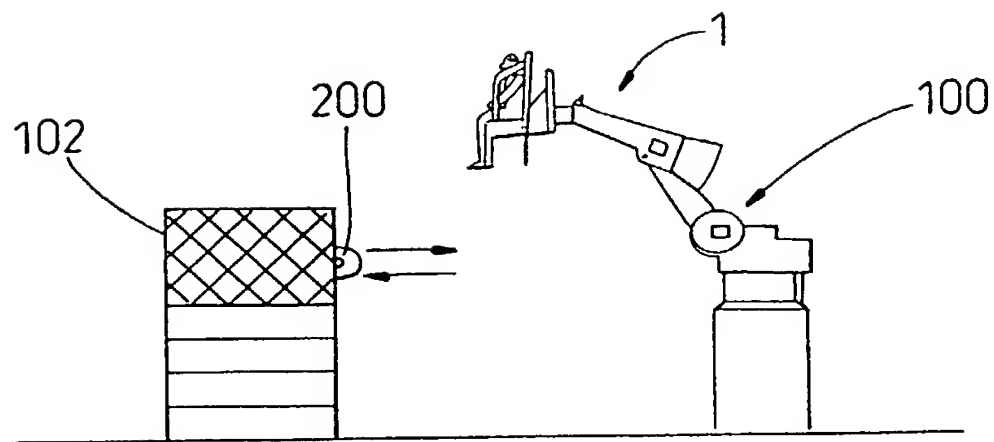


Fig. 8A

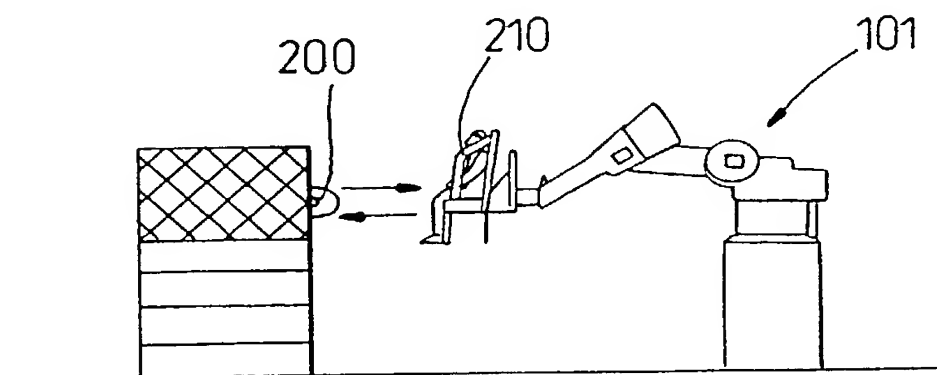


Fig. 8B

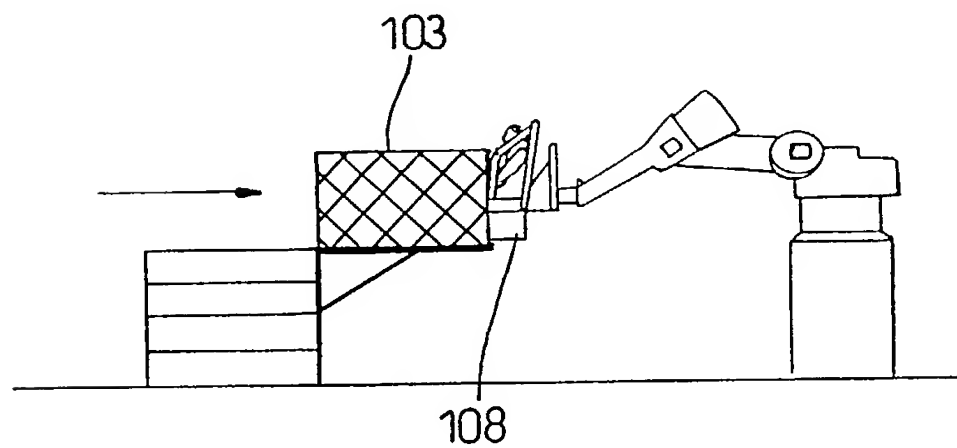


Fig. 8C

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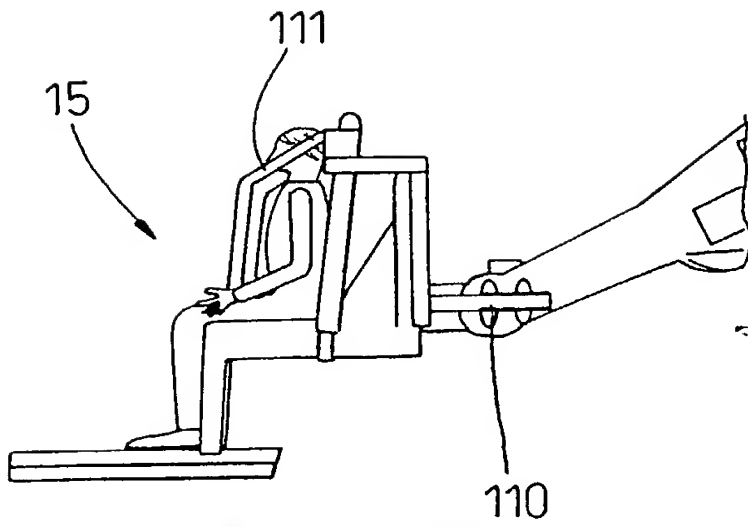


Fig. 9A

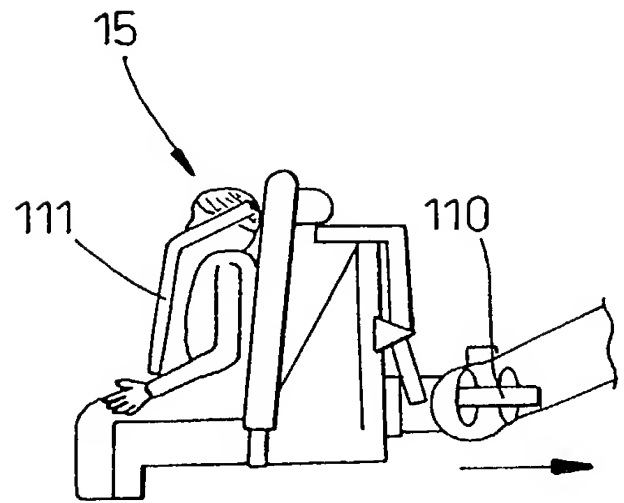


Fig. 9B

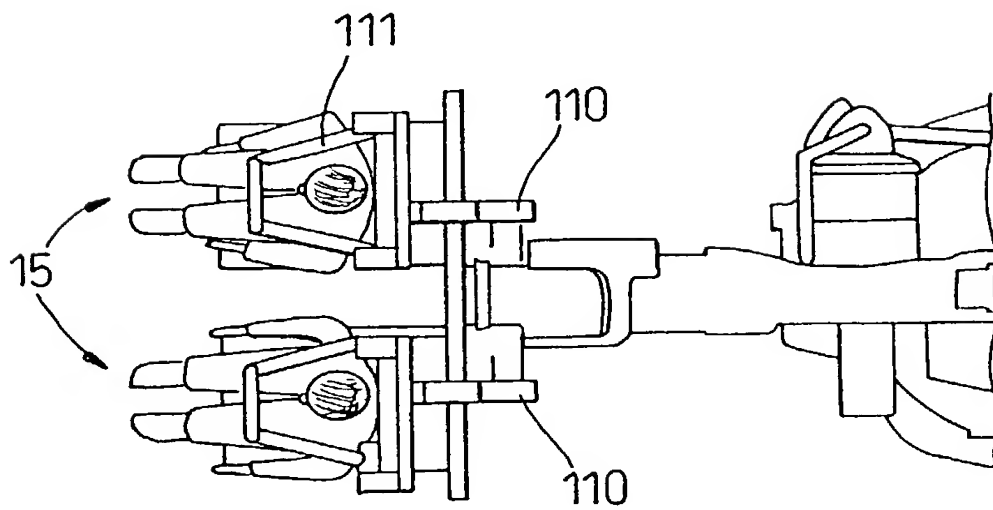


Fig. 9C

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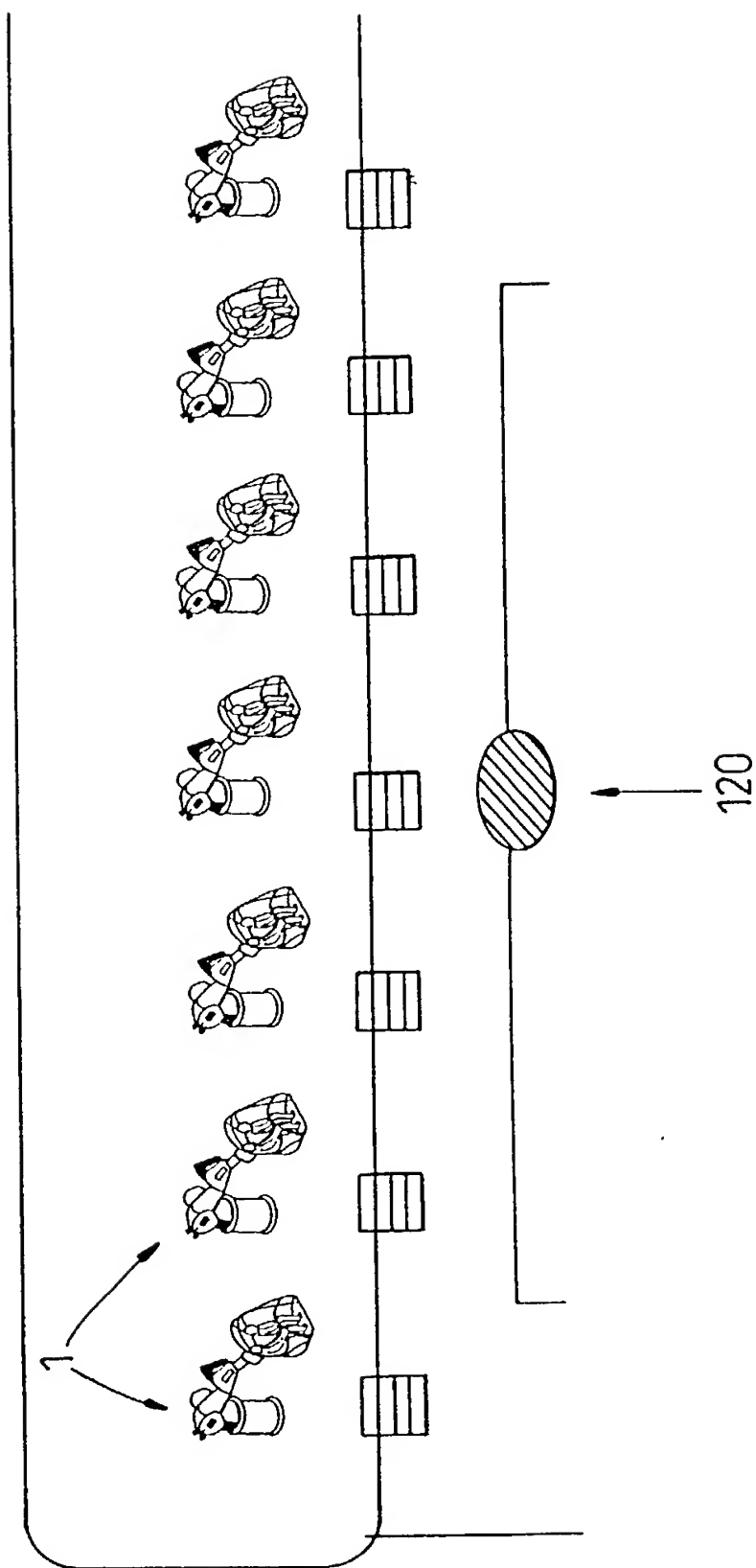


Fig. 10

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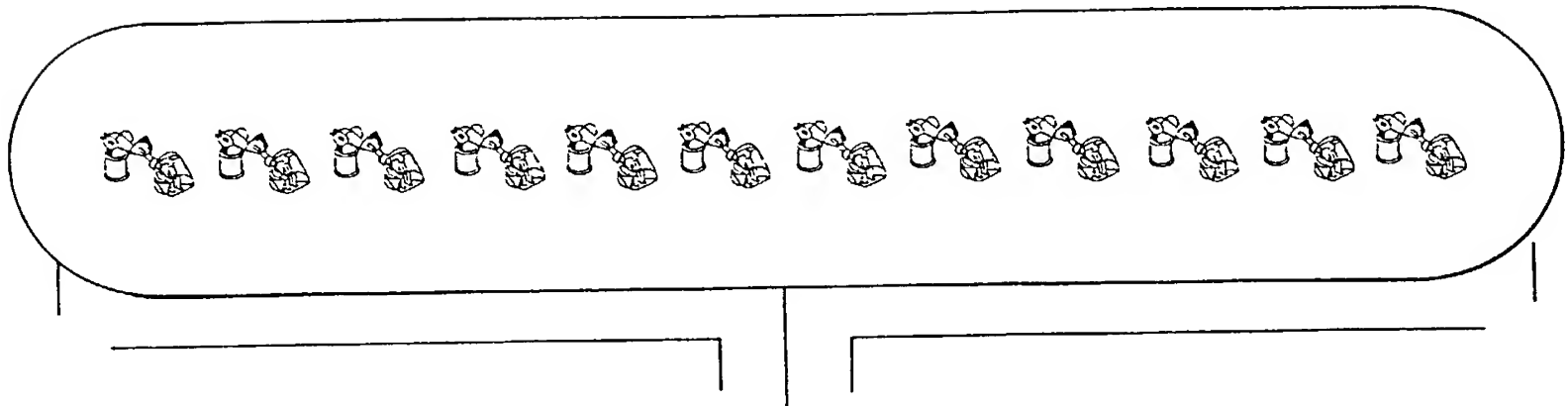


Fig. 11A

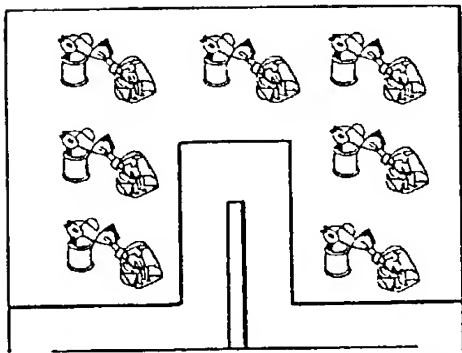


Fig. 11B

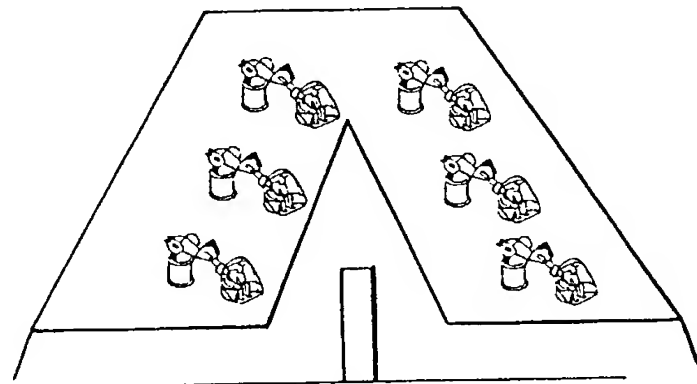


Fig. 11D

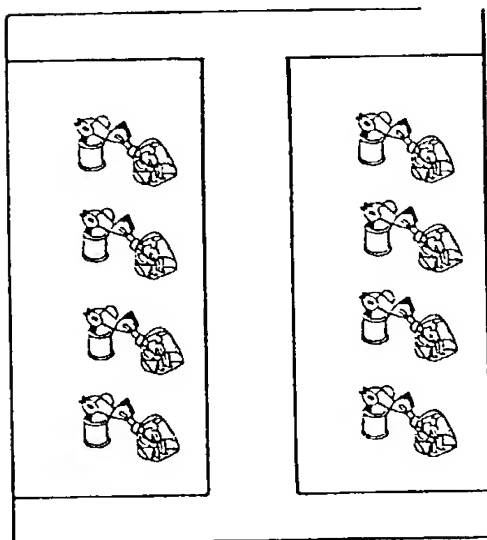


Fig. 11C

A schematic diagram of a robotic system. It features a central vertical axis with a curved arrow indicating rotation. Two robotic arms are positioned symmetrically on either side of the axis. Each arm has a base joint, a shoulder joint, and an end effector. The entire system is mounted on a base labeled 130. A label 2 points to the right arm's base joint.

Fig. 12B